

15



Europäisches Patentamt  
European Patent Office  
Office européen des brevets

(11) Publication number:

0 156 343  
A2

(12)

# EUROPEAN PATENT APPLICATION

(21) Application number: 85103490.0

(22) Date of filing: 25.03.85

(51) Int. Cl.<sup>4</sup>: G 06 K 9/80

(30) Priority: 26.03.84 JP 56044/84

(43) Date of publication of application:  
02.10.85 Bulletin 85/40

(84) Designated Contracting States:  
DE FR

(71) Applicant: HITACHI, LTD.  
6, Kanda Surugadai 4-chome Chiyoda-ku  
Tokyo 100(JP)

(72) Inventor: Suzuki, Kenji  
19-4, Hirasaku-1-chome  
Yokosuka-shi(JP)

(72) Inventor: Hata, Seiji  
20-10, Jonan-1-chome  
Fujisawa-shi(JP)

(72) Inventor: Miyakawa, Akira  
Kefmeiry, 850, Maiokacho  
Totsuka-ku Yokohama(JP)

(72) Inventor: Nishida, Yoshie  
Ishiso, 223, Bukkocho  
Hodogaya-ku Yokohama(JP)

(74) Representative: Patentanwälte Beetzsen. - Beetz jun.  
Timpe - Siegfried - Schmitt-Fumlan  
Steinsdorfstrasse 10  
D-8000 München 22(DE)

(54) Partial pattern matching method and apparatus.

(57) In a partial pattern matching system, a dictionary pattern, a pattern to be recognized and a binary-coding unit for giving a binary-coded image pattern by comparing each pixel with a predetermined voltage (10, 101 to 103) are provided. A polygonal approximation unit (104) gives a coordinate string of vertices of a polygon composed of a plurality of successive straight line segments approximately representing a contour of the binary-coded image pattern. A contour segmentation unit (106) judges a corner point among the vertex coordinates of the polygon based upon a criterion dependent upon the shape of the polygon, the corner point being used for dividing the polygon into a plurality of partial pattern. In a matching unit (107, 109), a correspondence pair is given by subjecting each combination of the partial patterns of the dictionary and recognition-object patterns to matching comparison, and each evaluation of matching degree is given for each of the correspondence pair.

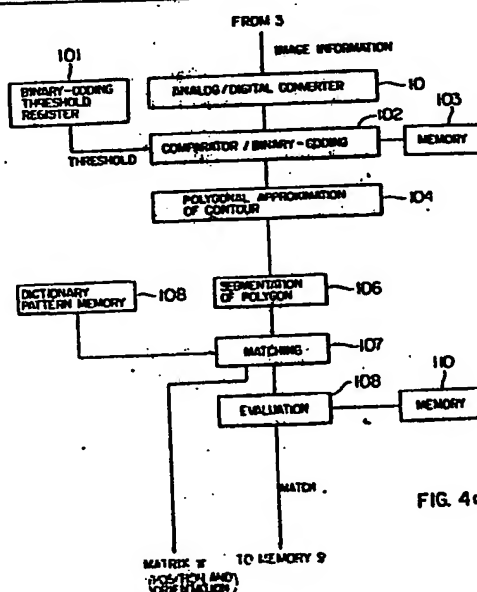


FIG. 4a

BEST AVAILABLE COPY

EP 0 156 343 A2

PARTIAL PATTERN MATCHING METHOD AND APPARATUS

1 BACKGROUND OF THE INVENTION

FIELD OF THE INVENTION

The present invention relates to parts recognition by image processing, and more particularly it  
5 relates to a partial pattern matching method suitable for recognizing incomplete parts patterns including therein such as superposed or broken-out portions.

In the Articles, Robert C. Bolles, "ROBUST  
FEATURE MATCHING THROUGH MAXIMAL CLIQUES", Proc. SPIE  
10 Technical Symposium on Imaging and Assembly, April, 1979;  
and Shigeyuki Sakane, "Segment Matching of Shapes Based  
on Clique Detection of Graphs" Electrotechnical Laboratory,  
PRL 82-84, February 1983, there is disclosed a pattern  
matching system in which a set of characteristics  
15 existing locally between a pattern to be recognized and  
a dictionary pattern are compared with one another.

With conventional parts recognition methods,  
if plural parts are superposed one upon another or if a  
portion of the part is broken away, an entire agreement  
20 of the recognized pattern shape with the part shape is  
not obtained so that characteristic values are not  
correctly sought. Therefore, a correct recognition  
could not be attained, e.g., failing in recognizing the  
superposed parts, or overlooking the partial difference  
25 of such parts as having a broken out portion.

1 SUMMARY OF THE INVENTION

It is an object of the present invention to provide a parts recognition method capable of attaining a high recognition rate with a low cost, which method  
5 is adapted to enable to recognize an incomplete pattern caused by superposition, breakage and the like of the parts thereby reducing the environmental conditions required for the recognition.

It is another object of the present invention  
10 to divide or segment, for the purpose of pattern recognition, a contour line of a two-dimensional image into partial or local patterns and to give the most proper indexes representative of the matching state of an incomplete contour.

15 It is still another object of the present invention to provide a method and apparatus in which a pattern recognition rate for the non-isolated or scattered object can be improved and the recognition can be achieved quickly.

20 In the preferred embodiment of the present invention, since an incomplete pattern coincides in part with a dictionary pattern, in recognizing the incomplete pattern, the pattern is segmented into local patterns so as to match the local pattern shape and its position.

25 In this case, in order to check the correspondence between the dictionary pattern and the local pattern of the pattern to be recognized, both dictionary and local patterns are divided into plural patterns in accordance

- 1 with the same criterion not depending upon the position  
and orientation of the patterns but depending upon only  
the contour shapes.

#### BRIEF DESCRIPTION OF THE DRAWINGS

- 5 Fig. 1 shows one example of automatic assembly  
systems to which the method and apparatus of the present  
invention is applicable, Fig. 2 is a schematic view  
showing the construction of an image processing unit,  
Figs. 3a and 3b are views showing examples of a  
10 dictionary pattern and parts pattern to be recognized,  
respectively, Fig. 4a is a schematic view showing the  
construction of a parts recognition unit, Fig. 4b is a  
parts recognition flow chart according to the present  
invention, Fig. 4c is a view showing binary-coding,  
15 Figs. 4d and 4e are views showing the processes of  
polygonal approximation of contour lines, Fig. 5a is a  
view showing the polygonal approximation and a segmen-  
tation of the polygon, Figs. 5b to 5f are views illus-  
trating the polygonal approximation, Fig. 6 is a detailed  
20 illustration of the local pattern matching process of  
Fig. 4a, Fig. 7 shows schematic illustrations for  
explaining the local pattern matching, and Fig. 8 shows  
schematic illustrations of the evaluation for the match-  
ing results of each local pattern.

#### 25 DESCRIPTION OF THE PREFERRED EMBODIMENTS

The embodiment of the present invention will

1 be described with reference to the accompanying drawings.  
Fig. 1 shows an automatic assembly station where a part  
supplied from a rotary parts feeder 1 is assembled on a  
chassis passing along a belt conveyor 2. The image of  
5 parts on the rotary parts feeder 1 is taken with a TV  
camera and input to an image processing unit 4. In  
the image processing unit 4, the presence or absence of  
a part to be assembled is recognized from the input  
image. If the part is present, the position and orien-  
10 tation of the part are calculated and the calculated  
results are transferred to an assembly robot 5. The  
assembly robot 5 moves its arm 5a in response to the  
information supplied from the image processing unit 4  
to grasp the part and assemble it. The rotary parts  
15 feeder 1 feeds the parts piled up on a center disk 1a  
to a peripheral truck 1b. The parts on the truck take  
arbitrary and two dimensional position and orientation  
so that the parts may contact one another or may be  
superposed in part one upon another. Thus, the image  
20 of the parts occasionally presents an incomplete pattern.

The arrangement of the image processing unit  
4 of Fig. 1 is shown in Fig. 2. An example of a  
dictionary pattern which is obtained in such a manner  
that a part to be used is photographed with the camera  
25 3 and the photographed image is converted into a binary  
code at an A/D converter of an image input board 10a,  
is shown in Fig. 3a. An example of a pattern to be  
recognized in which two parts are superposed one upon

1 the other is shown in Fig. 3b. The apparatus and  
process for the recognition are shown in Figs. 4a and  
4b, respectively. First, the image is input to an  
analog-to-digital converter 10 and converted into digital  
5 values each representative of the brightness of each  
pixel in the image (step S1). Based upon the comparison  
results of the digital value at a comparator 102 with a  
binary-coding threshold from a register 101, a binary  
image is obtained, in which the contour line of the  
10 pattern to be recognized represents to the boundary  
of black region and white region (step S2). Black-  
colored small squares in Fig. 4c represent contour  
line constituting pixels obtained through binary-coding.

The contour line or curve is approximated to  
15 a polygon made of several straight lines. First,  
the center of one of the contour points shown in Fig.  
4d is considered as a start point 201. The start  
point is registered as a vertex of a first approximated  
line segment. By introducing an imaginary circle  
20 having a radius  $\epsilon$  and a center  $P_i$  for the next contour  
point, an upper tangent angle TA2 and lower tangent  
angle TA1 relative to the start point are determined.  
In a similar manner, by introducing circles having  
radii  $\epsilon$  and centers of consecutive contour points,  
25 corresponding upper and lower tangents are determined.  
Among the obtained tangent angles, the maximum value  
of TA1 is represented by MAX(TA1) while the minimum  
value of TA2 is represented by MIN(TA2).

1           In the case that  $\text{MAX}(\text{TA1}) > \text{MIN}(\text{TA2})$  is established, it is decided that the approximation for the first line is no more possible. Then, the contour point at that time is considered as an end point of the first  
5 line and is registered.

          Candidate points for the end point are judged by assuring the fact that after the renewal of  $\text{MAX}(\text{TA1})$  and  $\text{MAX}(\text{TA2})$  obtained from the tangent lines, a line CA drawn passing through successive points is positioned  
10 between  $\text{MAX}(\text{TA1})$  and  $\text{MAX}(\text{TA2})$ . If the end point is not for the last data point, then using the point as a start point for approximation of another line, processings for approximating the other line are performed. For example, two parallel lines with a constant width 210  
15 may be used to determine a line ending at the vertex of the polygon.

          With such processings, a binary-coded image shown in Fig. 4c is transformed into a polygonally approximated contour made of a plurality of lines  
20 to 209 connected to each other as shown at the right of Fig. 4e. In a polygonal approximation unit 104 shown in Fig. 4a, the pattern contour 211 shown in Fig. 4c is approximated to a polygon. A set of coordinates  $(x_i, y_i)$  of the vertexes of the polygon are stored  
25 in a memory provided in the unit 104 (step S3). It is here noted that units 106 to 108 shown in Fig. 4a and described later include not shown memories, respectively. The vertex coordinates are given to a segmentation

1 unit 106 wherein the polygon made of plural line  
 segments is segmented in association with several charac-  
 teristic points of the polygon (step S4). Fig. 5a shows  
 an example of a polygonal approximation for the dictionary  
 5 pattern of Fig. 3a. As seen from the figure, among  
 angles between two adjacent sides, the angle (for example,  
 $\theta_1$ ) between the two sides on a smooth curve is small,  
 while the angle (for example,  $\theta_2$ ) between the two sides  
 on a corner of the pattern is large. By setting a suita-  
 10 ble threshold in the succeeding segmentation step, it  
 is possible to detect corners a, b, c, d, e, f, and g.  
 The coordinates of these corner points with flags set  
 and the remaining coordinates of the connection points  
 between line segments can be output to a matching device  
 15 107 (step S4).

The pattern as shown in Fig. 5a can definitely  
 be recognized. However, the recognition of an indeter-  
 minate projecting shape 122 of a pattern 121 shown in  
 a circle of Fig. 5b is unstable due to the coarseness  
 20 of pixels and displacement of the meshed pixels from  
 those of the pattern 121: in that the polygonal approx-  
 imation and segmentation may be performed to have either  
 line segments 123 with a single corner, or line  
 segments 124 with two corners, or line segments 125  
 25 with three corners. The more detailed description for  
 this is given with reference to Figs. 5c and 5d. In  
 the figures, x marks represent the centers of pixels.  
 The two thick lines connected at a point h correspond



1 to two line segments 127 and 128 after subjected to  
the polygonal approximation. The circle about the  
point h indicates that the point h has been judged as  
a corner or vertex.

5 In Fig. 5d, since the meshed pixels are some-  
what displaced as compared with those in Fig. 5c, the  
point 131 is positioned outside of two one-dot chain  
lines 140 and 141. In this case, another point i  
different from the point h in Fig. 5c is judged as a  
10 corner. Therefore, the rightmost point j on a line  
segment 138 will be recognized as a second corner.

In order to obviate the unstable recognition  
due to the mesh displacement described above, it is  
possible to adopt a judgement criterion as shown with  
15 Figs. 5e and 5f together with the judgement criterion  
using the foregoing angle threshold  $\theta_0$ . In particular,  
an angle  $\alpha_i$  is calculated by drawing broken lines 151  
and 152 passing through points  $k - n$ ,  $k + n$ , and  $k$ ,  
the points  $k - n$  and  $k + n$  being respectively apart  
20 from the point  $k$  by a certain number  $n$  ( $= 5$ , for example)  
of line segments. A similar calculation for an angle  
 $\alpha_{i+1}$  is performed between the point  $(k + 1)$  and points  
 $(k - n + 1)$  and  $(k + n + 1)$ . If any one of the angles  
is judged to have a smaller value than the preset  
25 threshold  $\alpha_0$ , then the corresponding point is recognized  
as a vertex and the other points can be excluded.  
Therefore, such segmentation as the lines 137 to 139  
shown in Fig. 5d is not brought about, but the point  $k$

1 apart from the pixel point h of Fig. 5c by a single  
pixel is judged as a vertex. Thus, a polygon similar  
in shape to that in Fig. 5c can be obtained.

Another vertex determination method will  
5 be described with reference to Fig. 5f. A certain  
number of contour line segments are chosen, and an  
arrow 162 is added. In the figure, a resultant vector  
162 of 10 vectors 161 is drawn on the middle vector in  
the vector train. Similar resultant vectors for respec-  
10 tive successive pixels are calculated. If the direction  
of the resultant vector has a large angle than a preset  
angle, then the corresponding pixel point is recognized  
as a vertex in the polygonal approximation. Thus,  
the unstable recognition as shown in Fig. 5d is avoided.

15 The processes up to step S4 for the segmentation  
of polygon described above with particular reference  
to Figs. 1 to 5f are performed first for the dictionary  
pattern and then for the pattern to be recognized in  
the practical field of pattern recognition applications.

20 The pattern recognition (step S5) carried out  
with the matching unit 107 and an evaluation unit 108  
will be described in detail. Although the dictionary  
pattern and the pattern to be recognized respectively  
shown in Figs. 3a and 3b have in general different  
25 shapes, those patterns include the same portions in  
part. Therefore, if there exist many and the same local  
patterns as those in the dictionary pattern at the  
positions not contradictory to the positions in the

1 dictionary pattern, the pattern to be recognized is  
judged as inclusive of the dictionary pattern.

The processes for the above judgement will  
be described with reference to Fig. 6. First, all of  
5 the combination of local patterns in the dictionary  
pattern and the pattern to be recognized are checked  
(step S51). Next, among the local patterns judged as  
having the same shape, every combination not contradictory  
to the positions in the dictionary pattern is sought  
10 (step S52). The similarity of both patterns is judged  
based whether or not the sought combinations occupy  
a substantially large portion of the dictionary pattern  
(step S53).

At first, step S51 in Fig. 6 will be described  
15 in detail with reference to Fig. 7. The distance between  
the start and end points of a local pattern and the sum  
of lengths of each line of the local pattern are used  
as auxiliary characteristic values. For each local  
pattern in the pattern to be recognized, those local  
20 patterns in the dictionary pattern which have the values  
d and l close to the values of the local pattern in the  
recognition pattern, are searched. For instance, B  
and G is selected for B'. Thereafter, B' is superposed  
upon B or G by coordinate transformation in order to  
25 check the coincidence between both local patterns. That  
is, in other words, the start and end points of both  
patterns are positioned as close as possible to each  
other, then all of the shortest distances  $P_i$  from the

- 1 vertiges of one pattern to the sides of the other pattern  
(for example, the length  $P_i$  of a perpendicular from a  
vertex of  $B'$  to the adjacent side of  $B$ ) is checked  
whether there is a longer distance than a preset threshold
- 5 D1. If it is decided to be coincident, coordinate  
transformation factors representative of a shift and  
rotation at that time are stored as a coordinate trans-  
formation matrix  $\pi$ . The adjacent side corresponding to  
vertex may be plural in number, thus the coincidence
- 10 judgement may be made when the sum  $\sum_i P_i$  of all of the  
lengths  $P_i$  between the vertices and sides becomes  
smaller than a preset threshold D2.

Step S52 in Fig. 6 will be described with  
reference to Fig. 8. The local pattern correspondence

15 between the patterns decided at step S51 as having the  
same shape is shown in Table (a). The coordinate  
transformation matrixes  $\pi_j$  ( $j = 1, 2, \dots$ ) shown as a  
mother group in Fig. 8 for all of the above decided  
patterns, are divided into group 1 and group 2 respec-

20 tively having almost the same coordinate transformation  
matrix value, by using a criterion judging whether  
the matrix value is within a permissible range or not.  
As a result, among the dictionary and the patterns to  
be recognized judged as having the same shape, only

25 those having not contradictory positional relations to  
each other as shown in Tables (b) and (c), i.e, groups  
of correspondence pairs of the local patterns can be  
obtained.

LOCAL PATTERN CORRESPONDENCE

Table (a)	Table (b)	Table (c)
A' - A	A - A'	A - E'
B' - B, G	B - B'	B - F'
C' - None	C	C - G'
D' - None	D	D - H'
E' - A	E	E - I'
F' - B, G	F	F
G' - C, F	G - L'	G
H' - D		
I' - E		
J' - None		
K' - None		
L' - B, G		

1           At step S53, the groups of the local patterns thus obtained are evaluated as to the degree of similarity.

The evaluation employs the following evaluation

5   function MATCH:

$$\text{MATCH} = \sum W_j \cdot f(j)$$

j: the local pattern number of the dictionary pattern

$W_j$ : weight of each local pattern of the dictionary

$$\text{pattern } \sum_j W_j = 1$$

$$f(j) = \begin{cases} "1": \text{indicative of the presence of the} \\ \quad \text{corresponding local pattern in the} \\ \quad \text{object pattern to be recognized} \\ "0": \text{indicative of the absence of such} \\ \quad \text{local pattern} \end{cases}$$

1           The weight  $W_j$  is previously determined depend-  
ing upon the importance of the characteristics of the  
local pattern. By setting a threshold for the value  
of the evaluation function, the groups of local patterns  
5 having the value of the evaluation function MATCH  
exceeding the threshold are judged as the same as the  
dictionary pattern shown in Fig. 3a for example.

Each local pattern belonging to the group  
which is judged having the same pattern as the dic-  
10 tionary pattern, is part of the dictionary pattern not  
contradictory to the position and orientation thereof.  
The calculated results of the position and orientation  
of the part pattern in the pattern to be recognized are  
sent to the robot. Although it is not necessarily the  
15 case that the position and orientation of the part  
pattern can be calculated from the position and orienta-  
tion of some local patterns, it is possible to obtain  
the position and orientation of the part pattern by all  
means if suitable threshold values of the evaluation  
20 function and weight  $W_j$  are set.

1           The present invention is not intended to be  
limited to the recognition of assembly parts for an  
assembly robot, but other pattern recognitions are also  
applicable. For example, the present invention is  
5 applicable to a character recognition in which each  
stroke in a thin character is recognized as a local  
pattern and the above evaluation function is used.  
Another application is to such a case as an additional  
part is mounted on a movable part on a mechanical base  
10 plate wherein the contour of the movable part is  
indefinitely recognized because of the unstable condition  
of the background of the base plate.

          According to the above embodiments, it is  
effective in that the recognition rate and speed for  
15 generally incomplete parts can be improved.

1 CLAIMS:

1. A partial pattern matching method for recognizing an object pattern by comparing a dictionary pattern with the recognition-object pattern comprising the steps of:

5 (a) approximating (S1, S2, S3) a contour line of a region in a two dimensional image for the recognition-object pattern to a pattern having a plurality of consecutive line segments basing upon a criterion depending only upon the shape of said contour line;

10 (b) contour segmenting (S4) said polygon pattern basing upon the shape of said polygon pattern into a partial pattern having at least one polygon edge; and

(c) matching (S5) said partial patterns of  
15 said dictionary pattern and recognition-object patterns.

2. A method according to claim 1, wherein said approximation step (a) includes a step of giving the coordinates of each vertex of a polygon approximated to said contour line, and said step (c) matches said  
20 local patterns by weighting each local pattern in accordance with the contribution to the characteristics of the shape of said dictionary pattern.

3. A method according to claim 1, wherein said contour segmenting step (b) uses as a division vertex  
25 of said partial pattern a polygonal vertex where the angle between the directions of one of said plurality of successive line segments and an adjacent line segment



1 changes to a large degree.

4. A method according to claim 1, wherein each  
of said partial patterns of said dictionary pattern  
and recognition-object pattern has a simple shape as  
5 a whole without an inflection point.

5. A method according to claim 4, wherein said  
matching step (c) includes the steps of: setting as a  
first characteristic amount the distance between both  
ends of each of said partial pattern and the sum of line  
10 segments on each of said partial pattern; selecting the  
partial pattern having said first characteristic amount  
within a preset error range and setting as a second  
characteristic amount the position and orientation of  
each selected partial pattern; and setting as a matrix  
15 the amount of shift and rotation for transforming the  
coordinates of one of the partial pattern to the other  
of the partial pattern.

6. A method according to claim 5 further com-  
prising:  
20 a step of classifying said partial pattern  
having the value of said matrix within a preset error  
range into the same group;

a step of giving an index indicative of the  
presence or absence, within said same group, of the  
25 partial pattern of said recognition-object pattern  
corresponding to the partial pattern of said dictionary  
pattern;

a step of setting for each partial pattern of

1 said dictionary pattern a weight dependent upon the  
characteristics of the contour of said each partial  
pattern; and

a step of giving an evaluation function wherein  
5 the multiplication of said index by said weight is  
added for all of the combinations of partial patterns  
within said same group.

7. A partial pattern matching method for recognizing a recognition-object pattern by comparison with a  
10 dictionary pattern comprising the steps of:

(a) binary-coding a two dimensional image  
obtained by photographing an object relative to the  
plurality of minute digital pixels and giving an image  
data representative of a contour line of said image;

15 (b) approximating the image data representative  
of said contour line to a polygon having a plurality  
of successive line segments basing upon a criterion  
determining opposite ends of a line segment in accordance  
with a criterion that successive pixels are inside of  
20 two parallel going lines set in the direction of the  
successive pixels at a predetermined space therebetween,  
and giving a string of coordinates representative of  
respective vertices of said polygon;

(c) dividing said polygon, by using said line  
25 segment included in said polygon as a unit, into a  
plurality of partial patterns relative to each division  
vertex where the directions of said line segments change  
by a larger angle than a preset angle, and adding a flag

1 to the coordinates representative of said division  
vertex (S4);

(d) storing into a memory partial pattern  
collections for respective said recognition-object  
5 pattern and dictionary object pattern by performing  
the steps (a) to (c);

(e) selecting a pair of partial patterns among  
the pairs derived one by one from each of said partial  
pattern collections, said selected pair having a  
10 smaller difference than a preset value between the values  
of each sum  $l_1$  and  $l_2$  of line segments on the paired  
partial pattern and the values of each distance  $d_1$  and  
 $d_2$  between start and end points of said paired partial  
pattern, and giving a coordinate transformation matrix  
15 for the alignment of the position and orientation of  
one of said paired partial patterns with the other of  
said paired partial patterns (S51);

(f) classifying said coordinate transformation  
matrix obtained for each partial pattern into the same  
20 group if the value of said matrix is within a preset  
error range, and giving an index  $f(j)$  which differs  
depending upon the presence or absence of said partial  
pattern of said dictionary pattern (S52); and

(g) giving an evaluation function  $MATCH =$   
25  $\sum_j W_j \cdot f(j)$  by adding for each group the multiplication  
results of a preset weight  $W_j$  given to each of said  
partial pattern of said dictionary pattern.

8. A method according to claim 7, wherein said

1 polygonal approximation step (b) includes the steps  
of: giving in succession to each pixel a resultant  
vector (162) of a predetermined number of vectors each  
indicative of the distance and direction associated with  
5 adjacent two of said pixels; and setting as a vertex  
of said polygon a point where said successive resultant  
vector changes to a large extent exceeding a preset  
range.

9. A method according to claim 7, wherein said  
10 polygonal approximation step (b) includes the steps of:  
giving an angle  $\alpha_i$  between two straight lines passing  
through each of said pixels on said contour line and  
respective two pixels being oppositely positioned  
apart by a certain number of pixels from said each of  
15 said pixels; and setting as a vertex of said polygon  
a pixel where said angle  $\alpha_i$  is smaller than a preset  
angle.

10. A partial pattern matching system for a  
dictionary pattern and a recognition-object pattern  
20 comprising:

(a) binary-coding means input with an image  
information for giving a binary-coded image pattern by  
comparing each pixel with a predetermined voltage  
(10, 101, 102, 103);

25 (b) polygonal approximation means for giving  
a coordinate string of apexes of a polygon composed of  
a plurality of successive straight line segments  
approximately representing a contour of said binary-

1 coded image pattern (104);

(c) contour segmentation means for judging  
a corner point among the vertex coordinates of said  
polygon basing upon a criterion dependent upon the shape  
5 of said polygon, said corner point being used for dividing  
said polygon into a plurality of partial patterns (106);

(d) means for providing a correspondence pair  
by subjecting each combination of said partial patterns  
of said dictionary and recognition-object patterns to  
10 matching comparison (107, 109); and

(e) means for evaluation of matching of each  
of said correspondence pair (108, 110).

FIG. 1

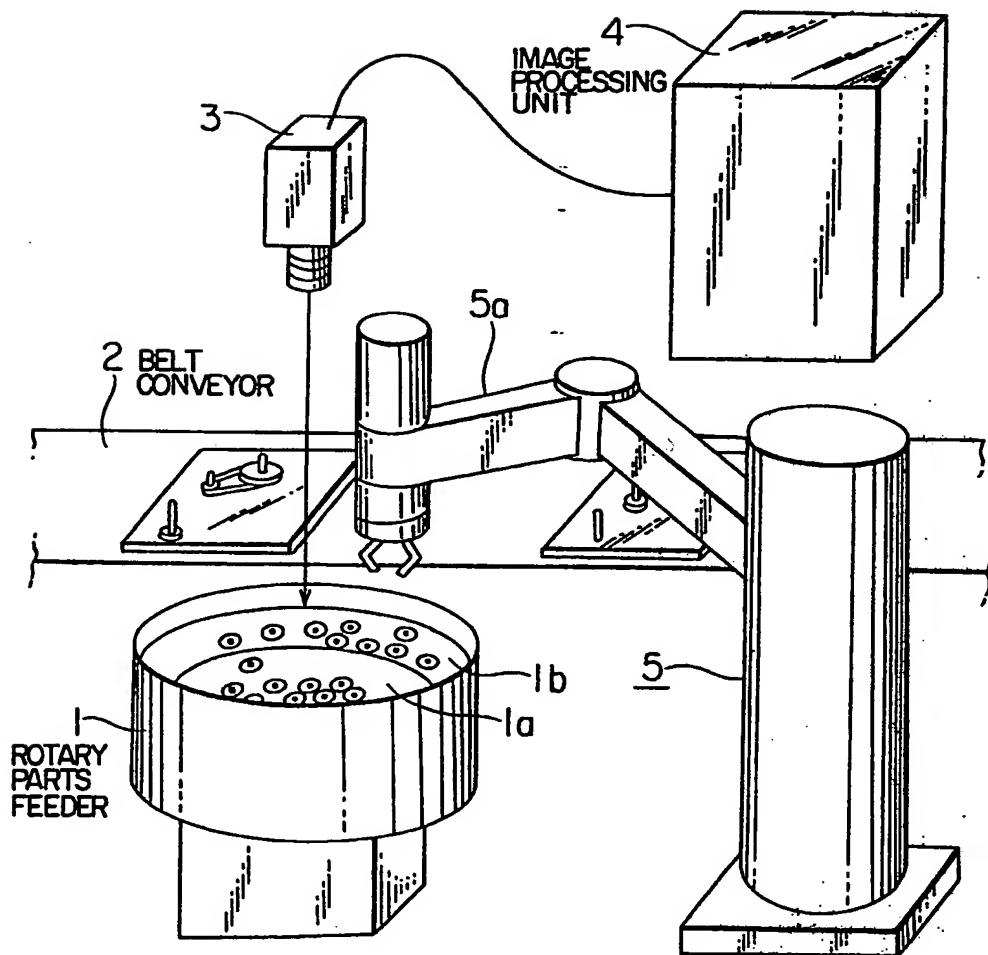


FIG. 2

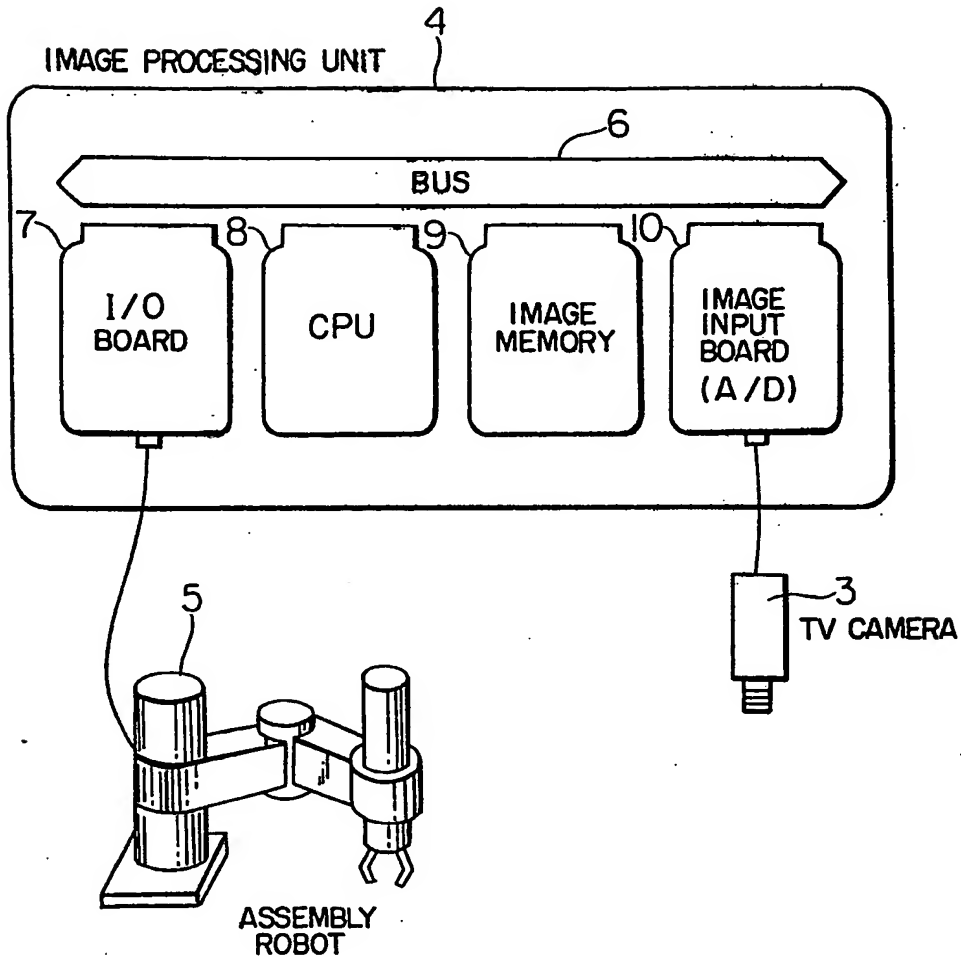
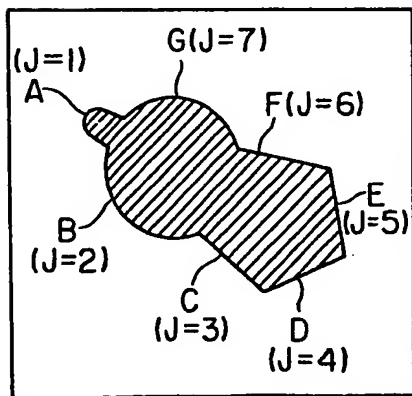
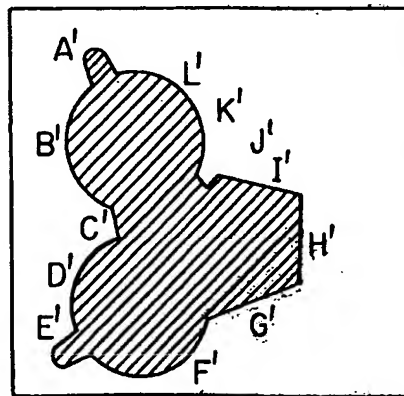


FIG. 3a



DICTIONARY PATTERN

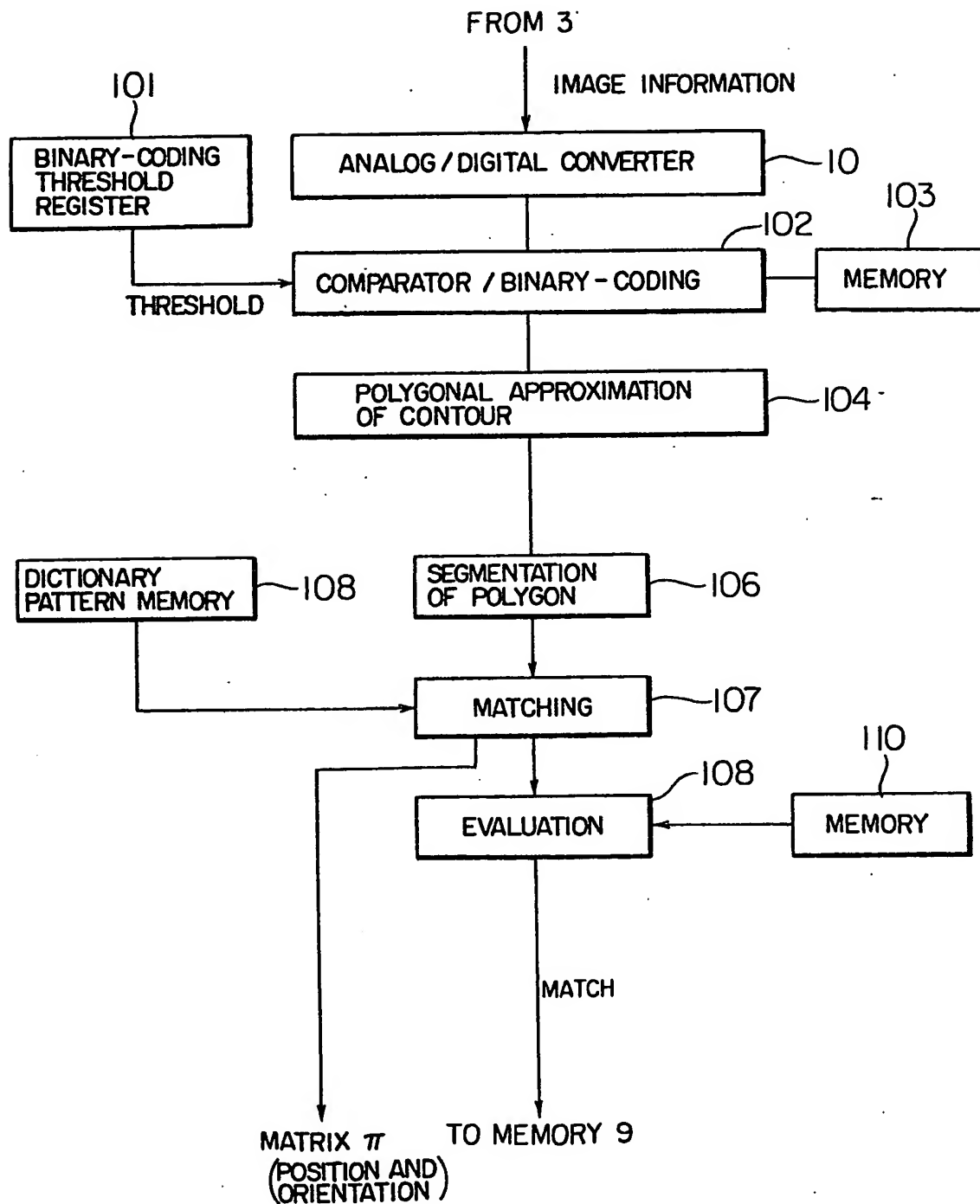
FIG. 3b



PATTERN TO BE RECOGNIZED

3/10

FIG. 4a





**FIG. 4c**

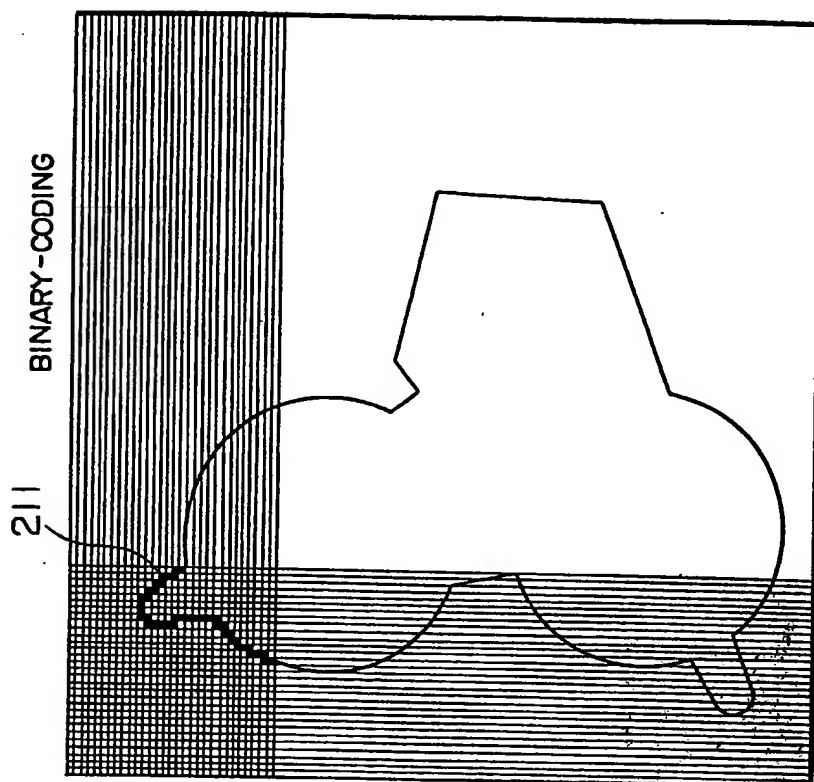


FIG. 4b

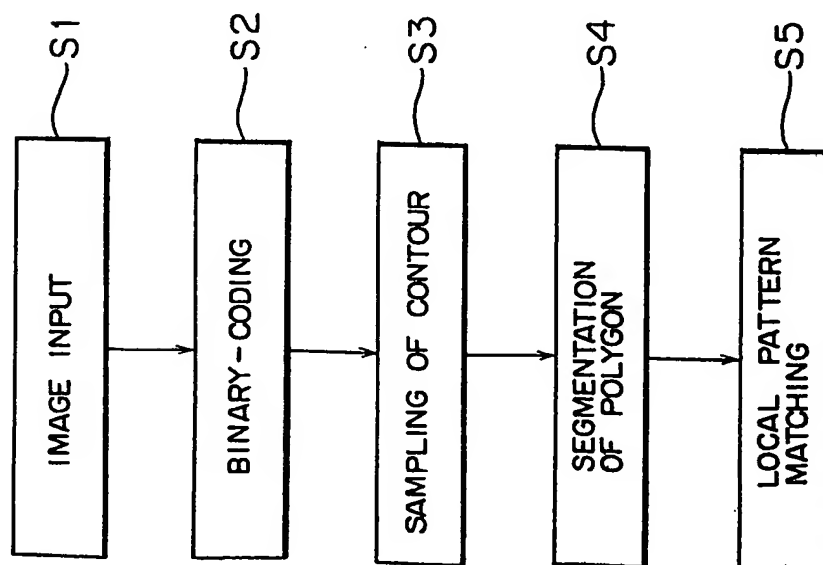


FIG. 4d

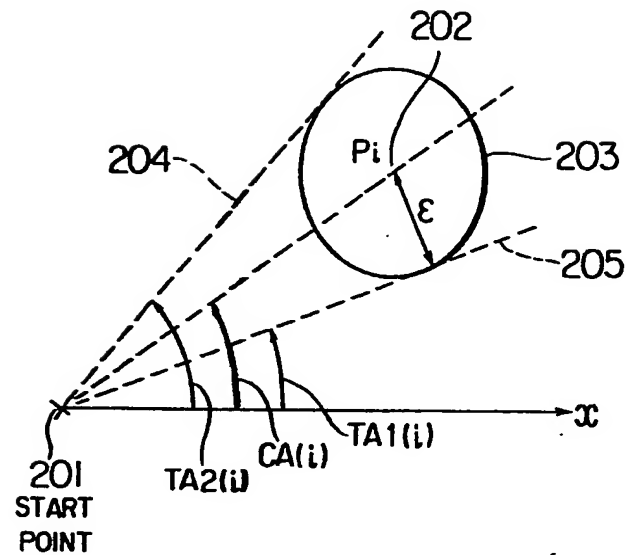


FIG. 4e

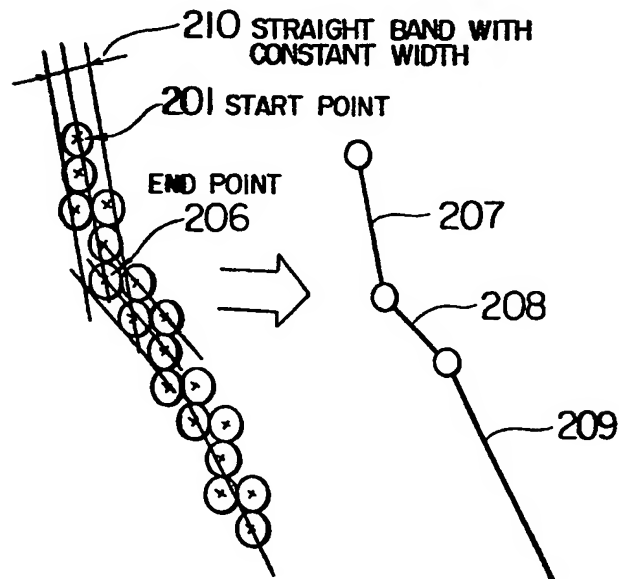


FIG. 5a

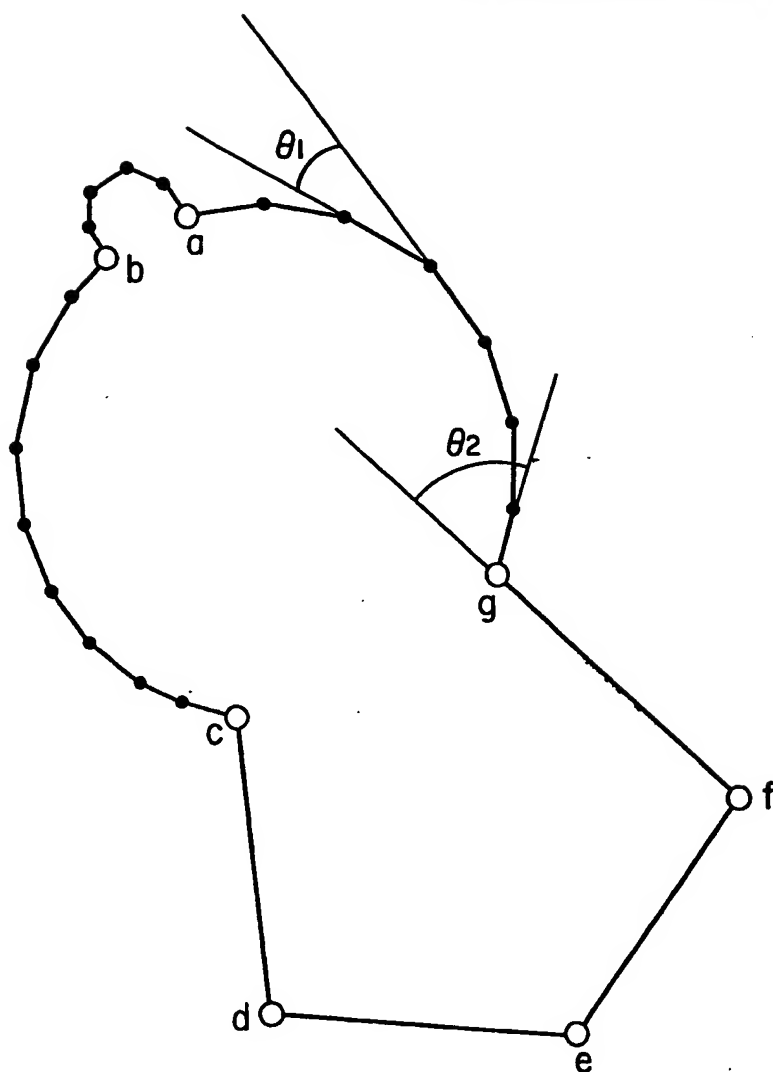
POLYGONAL APPROXIMATION  
AND SEGMENTATION OF POLYGON

FIG. 5b

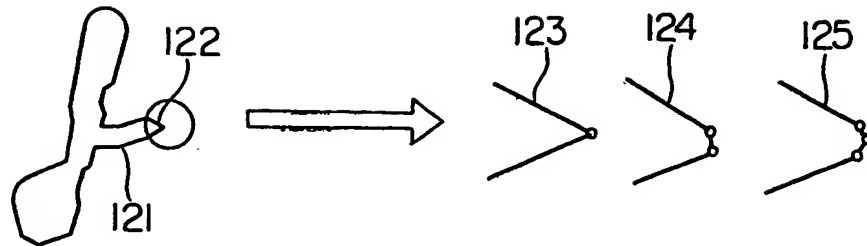


FIG. 5c

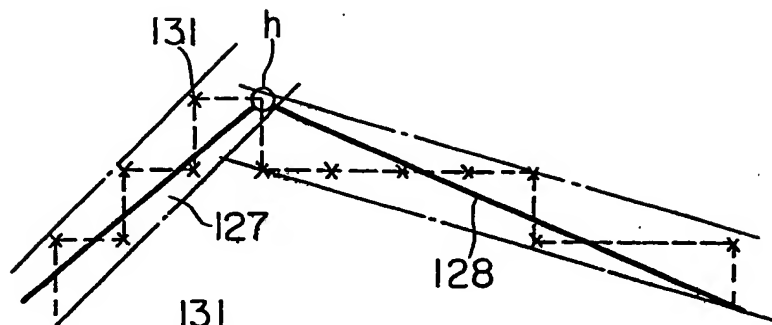


FIG. 5d

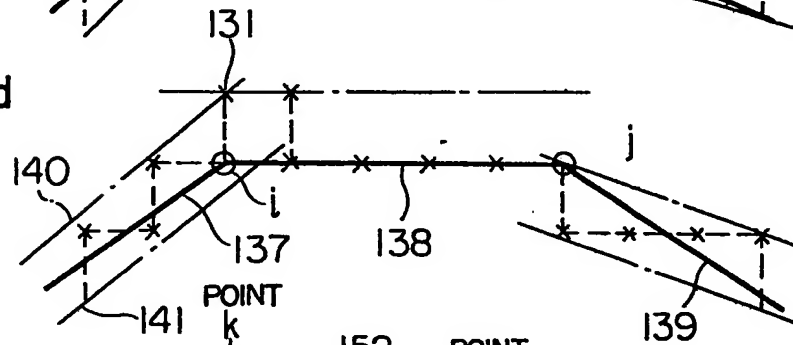


FIG. 5e

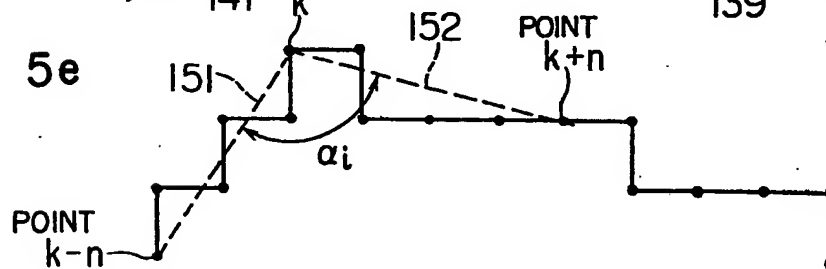


FIG. 5f

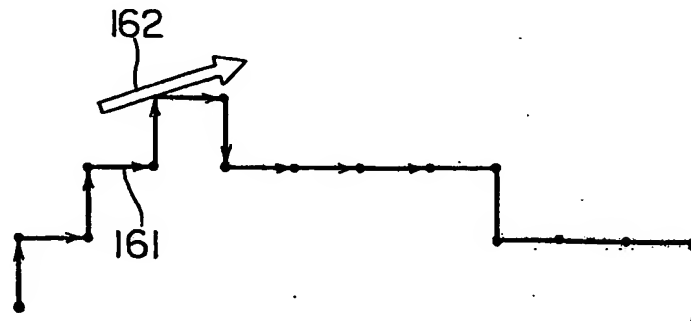
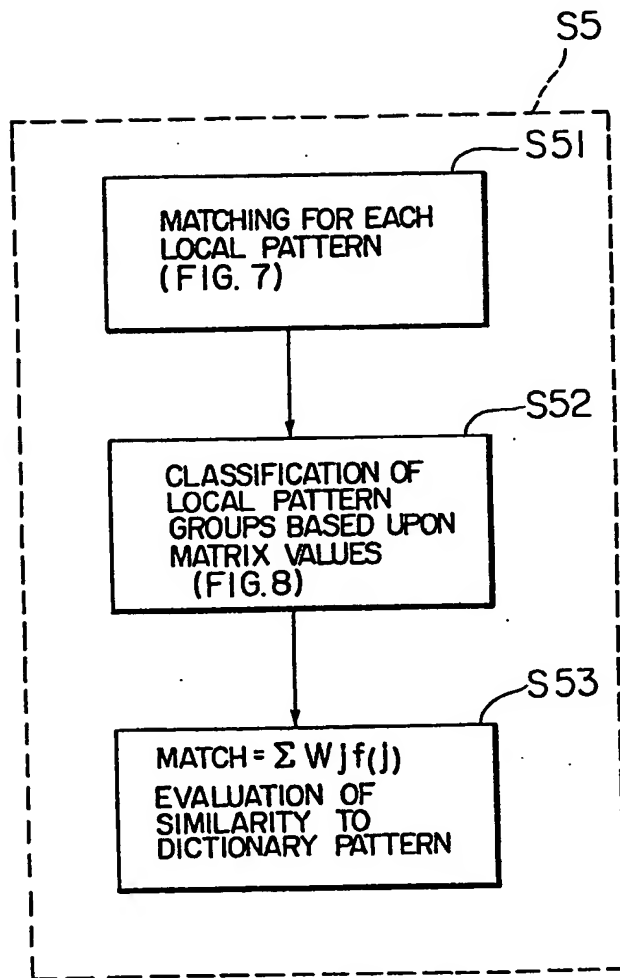
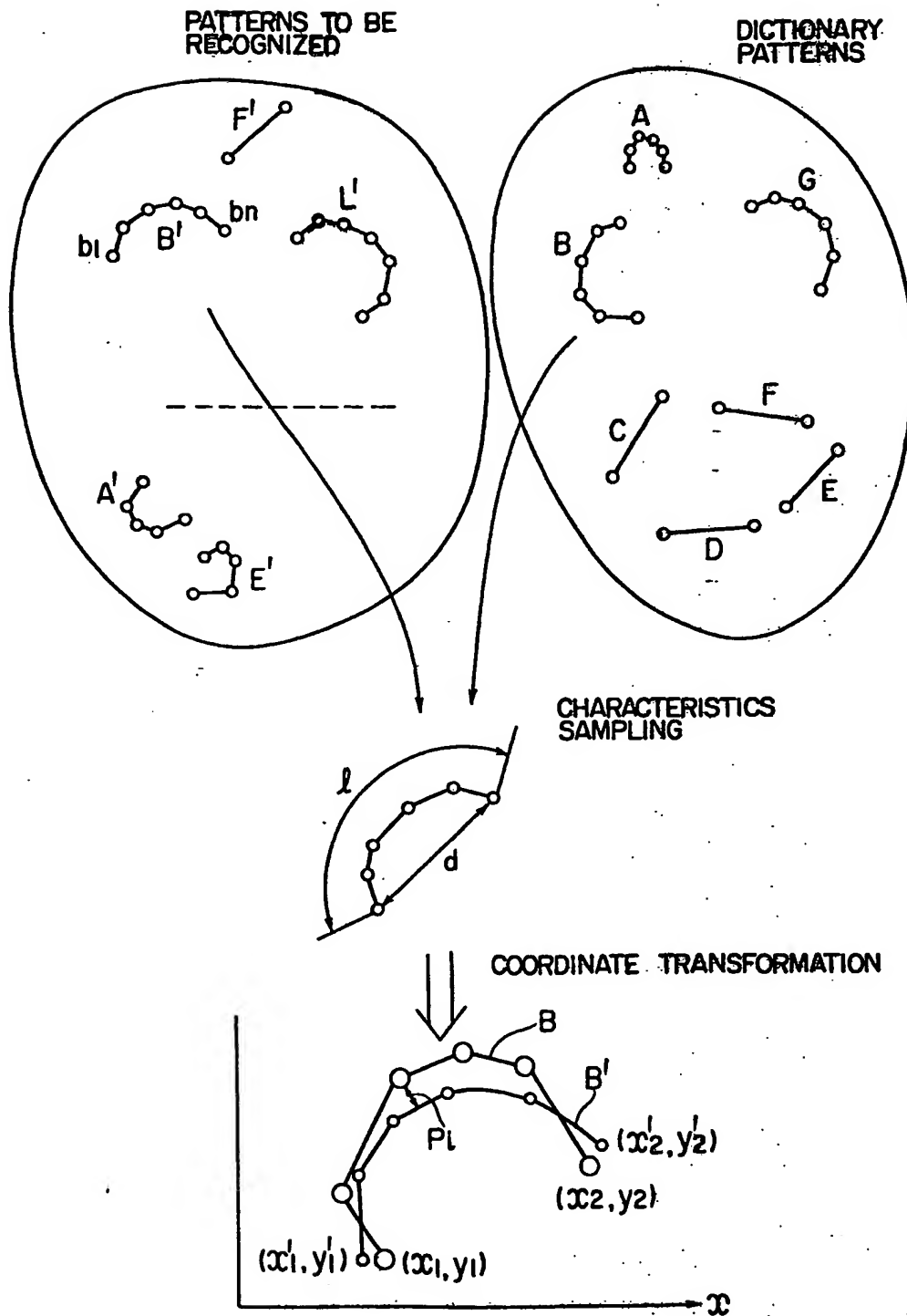


FIG. 6

POLYGONAL APPROXIMATION  
OF PARTS PATTERN

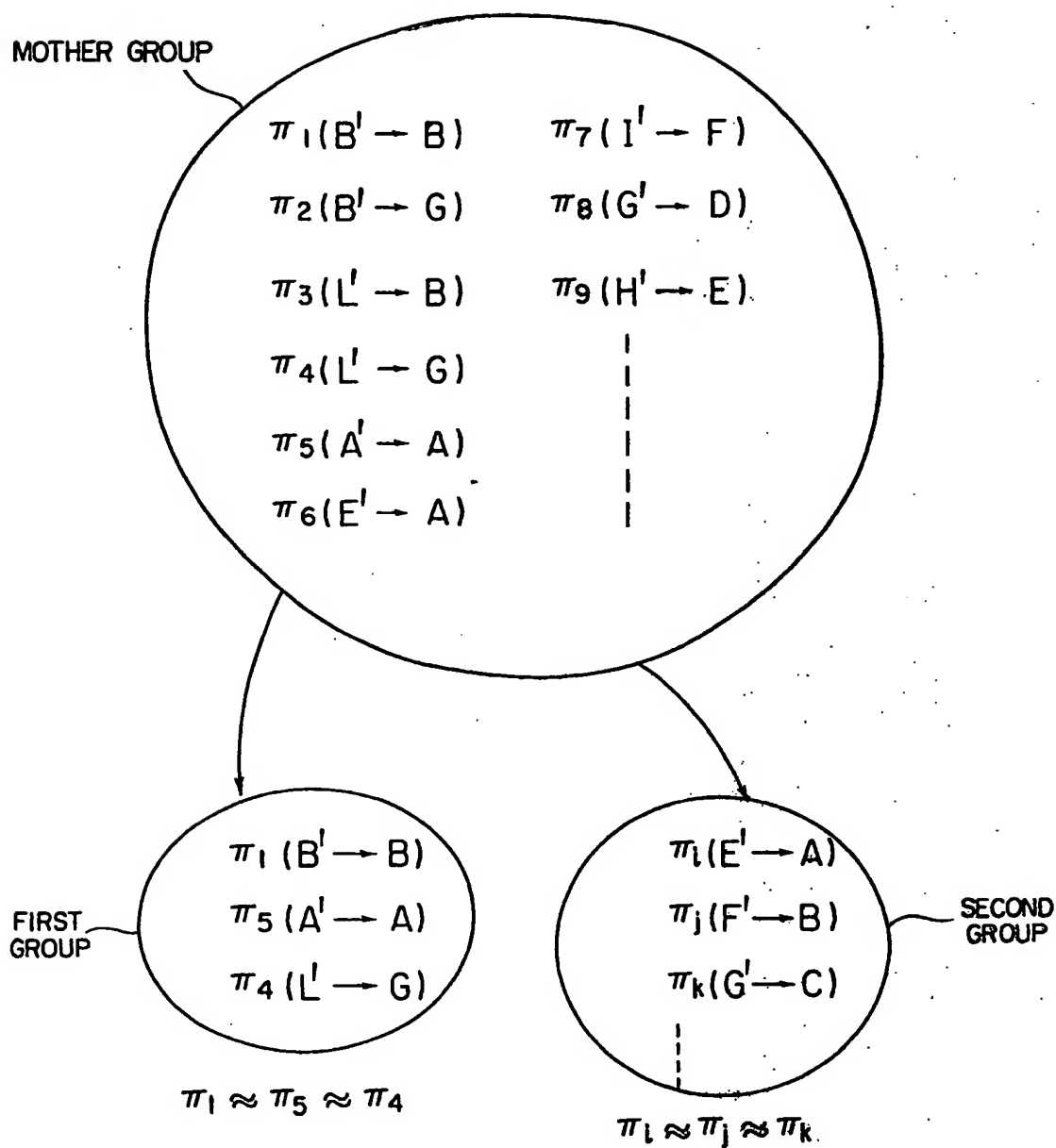
9/10

FIG. 7



10/10

FIG. 8



**This Page is Inserted by IFW Indexing and Scanning  
Operations and is not part of the Official Record**

### **BEST AVAILABLE IMAGES**

Defective images within this document are accurate representations of the original documents submitted by the applicant.

Defects in the images include but are not limited to the items checked:

- ☒ **BLACK BORDERS**
- ☐ **IMAGE CUT OFF AT TOP, BOTTOM OR SIDES**
- ☐ **FADED TEXT OR DRAWING**
- ☒ **BLURRED OR ILLEGIBLE TEXT OR DRAWING**
- ☐ **SKEWED/SLANTED IMAGES**
- ☐ **COLOR OR BLACK AND WHITE PHOTOGRAPHS**
- ☐ **GRAY SCALE DOCUMENTS**
- ☒ **LINES OR MARKS ON ORIGINAL DOCUMENT**
- ☐ **REFERENCE(S) OR EXHIBIT(S) SUBMITTED ARE POOR QUALITY**
- ☐ **OTHER: \_\_\_\_\_**

### **IMAGES ARE BEST AVAILABLE COPY.**

**As rescanning these documents will not correct the image problems checked, please do not report these problems to the IFW Image Problem Mailbox.**